Abstract

A method for controlling the speed of a vehicle (1) is proposed, where, in the vehicle (1) to be controlled, the yaw rate or rotation rate is measured, in particular to determine the curvature (k) of the vehicle's own travel trajectory, and where, using a proximity sensor or position sensor (6), at least one vehicle (5,8) traveling ahead or at least some other object within a sensor's sensing range (7) is detected, particularly with regard to an offset from the travel course of the vehicle to be controlled. By delaying the travel-course offset (yc) of a vehicle (5) driving ahead, determined in preset measuring cycles, by a predefined time span (t_{hist}), and by using the then instantaneous curvature (k) of the travel trajectory, a historical travel-course offset (yc_{hist}) is ascertained, one is able to simply and rapidly predict the travel course of the vehicle (1) to be controlled.

(Figure 1)